

IN THE CLAIMS:

Please amend the claims as follows:

1. **(Original)** A hand device for working robot comprising:

 a grip capable of gripping or releasing a workpiece;

 a movable body provided on a driving base so as to extend or retract by a driving means;

 a link means for linking an extending or retracting movement of the movable body with a gripping or releasing movement of the grip; and

 a workpiece drop prevention means for preventing a workpiece from dropping by attaching to the movable body to stop the releasing movement of the grip when the driving means is stopped,

 wherein the workpiece drop prevention means further comprises a protrusion stick with a tapered tip, a support rail supporting the protrusion stick so as to slide the protrusion stick between a protrusion position where the protrusion stick abuts on the movable body and a recess position, a momentum means for pushing the protrusion stick supported by the support rail at the protrusion position, and a holding means for holding the protrusion stick at the recess position resisting against the pushing of the momentum means in a normal state and for releasing the protrusion stick when the driving means is stopped operating.

2. **(Original)** A hand device for working robot according to claim 1, wherein the holding means controls gripping and releasing the protrusion stick by the driving means of the movable body.

3. **(Currently Amended)** A hand device for working robot according to claim 1, wherein the grip has at least a pair of fingers mounted pivotally on ~~the~~ a gripping base and movement of gripping and releasing the workpiece are performed from both lateral sides of the workpiece by rotating the fingers around a pivot axis.

4. **(Currently Amended)** A hand device for working robot according to claim 2, wherein the grip comprising at least a pair of fingers mounted pivotally on ~~the~~ a gripping base and movement of gripping and releasing the workpiece is performed from both lateral sides of the workpiece by rotating the fingers around a pivot axis.

5. **(Original)** A hand device for working robot according to claim 3, wherein the link means includes a lever protruding from the base of the fingers and a connecting pad for connecting the lever and the movable body, and an extending and retracting movement of the movable body is linked with a rotating movement of the fingers.

6. **(Original)** A hand device for working robot according to claim 4, wherein the link means includes a lever protruding from the base of the fingers and a connecting pad for connecting the lever and the movable body, and an extending and retracting movement of the movable body is linked with a rotating movement of the fingers.